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## USER MANUAL

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<b>1</b>	<b>INTRODUCTION.....</b>	<b>5</b>
<b>2</b>	<b>OPERATING INSTRUCTIONS .....</b>	<b>6</b>
2.1	HANDLING PRECAUTIONS .....	6
2.2	ACCEPTANCE TESTS.....	6
2.2.1	<i>Inventory</i> .....	6
2.2.2	<i>Physical Inspection</i> .....	6
2.3	DEFAULT PARAMETERS .....	6
2.3.1	<i>ARGO Identification</i> .....	6
2.3.2	<i>Decoding</i> .....	6
2.4	LAUNCHING.....	7
2.4.1	<i>Test the Float and arm the mission</i> .....	7
2.4.2	<i>Remove protective plugs and magnet</i> .....	7
2.4.1	<i>Deployment checklist</i> .....	8
2.4.2	<i>Launch the Float</i> .....	9
2.5	CHECKS PRIOR TO DEPLOYMENT .....	10
2.5.1	<i>Necessary Equipment</i> .....	10
2.5.2	<i>Connecting the PC</i> .....	10
2.5.3	<i>Example of Bluetooth dongle tested by NKE</i> .....	12
2.5.4	<i>How to Send Commands</i> .....	13
2.5.5	<i>How to Read and change Parameter Values</i> .....	13
2.5.6	<i>How to Check and change the Time</i> .....	14
2.5.7	<i>Configuration Check</i> .....	15
2.5.8	<i>Functional Tests</i> .....	15
<b>3</b>	<b>GENERAL DESCRIPTION OF ARVOR-DEEP FLOAT .....</b>	<b>17</b>
3.1	ARVOR-DEEP .....	17
3.2	HULL .....	18
3.3	MAGNET POSITIONS.....	18
3.4	DENSITY CONTROL SYSTEM.....	18
3.5	SENSORS .....	18
3.6	IRIDIUM/GPS MODEM .....	18
3.7	CPU BOARD.....	19
3.8	BATTERY .....	19
3.9	MMI LINK.....	19
<b>4</b>	<b>THE LIFE OF AN ARVOR-DEEP FLOAT .....</b>	<b>19</b>
4.1	THE MISSION - OVERVIEW.....	19
4.2	DESCENT .....	21
4.3	GROUNDING .....	21
4.4	SUBMERGED DRIFT .....	22
4.5	ASCENT.....	22
4.6	TRANSMISSION .....	22
<b>5</b>	<b>ARVOR-DEEP PARAMETERS .....</b>	<b>23</b>
5.1	MISSION PARAMETERS .....	23
5.2	USER COMMANDS .....	25
<b>6</b>	<b>IRIDIUM FORMATS.....</b>	<b>27</b>
6.1	OVERVIEW .....	27
6.2	TECHNICAL MESSAGE 1 (TYPE =0).....	28
6.3	TECHNICAL MESSAGE 2 (TYPE = 4).....	30
6.4	DESCENT PROFILE CTD MESSAGE (TYPE = 1) .....	32
6.5	SUBMERGED DRIFT CTD MESSAGE (TYPE = 2).....	32
6.6	ASCENT PROFILE CTD MESSAGE (TYPE = 3).....	32
6.7	DESCENT PROFILE CTDO MESSAGE (TYPE = 8).....	33
6.8	SUBMERGED DRIFT CTD MESSAGE (TYPE = 9).....	33
6.9	ASCENT PROFILE CTD MESSAGE (TYPE = 10).....	33

6.10	CTD DATA TREATMENT DETAILS .....	34
6.10.1	Zone & Slice thickness .....	34
6.10.2	Decimation.....	35
6.10.3	Averaging .....	36
6.11	PARAMETERS DATA MESSAGE (TYPE = 5) .....	36
6.12	HYDRAULIC MESSAGE EV (TYPE = 6).....	38
6.13	HYDRAULIC MESSAGE PUMP (TYPE = 7).....	38
6.14	LIFE EXPIRY MESSAGE.....	39
6.14.1	Phase description.....	39
6.15	IRIDIUM COMMMANDS.....	39
6.15.1	Telecommand SBD File creation.....	40
6.15.2	Sending an SBD Message (telecommand) to the 9602-LP.....	40
7	SPECIFICATIONS.....	42
8	ARVOR-DEEP OPERATING PRINCIPLE.....	43
9	LITHIUM BATTERY .....	44
10	GLOSSARY .....	45

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PRELIMINARY

### 1 INTRODUCTION

ARVOR-DEEP is a subsurface profiling float developed jointly by IFREMER and nke instrumentation. Since January 1st, 2009 **nke** has integrated profiling floats activity and is now in charge of ARVOR-DEEP manufacturing and development in industrial partnership with IFREMER.

The ARVOR-DEEP float described in this manual is designed for the ARGO Program. This international program will be a major component of the Global Ocean Observing System (GOOS). An array of 3,000 free-drifting profiling floats is planned for deployment in 2004. These floats will measure the temperature and salinity of the upper 2,000 meters of the ocean, allowing continuous monitoring of the ocean's climate.

All Argo measurements will be relayed and made publicly available within hours after collection. The data will provide a quantitative description of the evolving state of the upper ocean and the patterns of ocean climate variability, including heat and freshwater storage and transport. It is expected that ARGO data will be used for initialization of ocean and coupled forecast models, and for dynamic model testing. A primary focus of Argo is seasonal to decadal climate variability and predictability.

After launch, ARVOR-DEEP's mission consists of a repeating cycle of descent, submerged drift, ascent and data transmission. During these cycles, ARVOR-DEEP dynamically controls its buoyancy with a hydraulic system. This hydraulic system adjusts the density of the float causing it to descend, ascend or hover at a constant depth in the ocean. The user selects the depth at which the system drifts between descent and ascent profiles. ARVOR-DEEP continually samples the pressure at this drift depth and maintains that depth within approximately 30m.

After the submerged drift portion of a cycle, the float proceeds to the depth at which the ascending profile is to begin. The ascent profile starting depth (typically the ARGO-selected depth of 2,000m) is not necessarily the same as the drift depth.

During its mission, ARVOR-DEEP collects measurements of 3 or 4 parameters - salinity, temperature and depth (CTD) with optional dissolved oxygen - and saves them in its memory. These measurements can be made during the float descent (descent profile), during the submerged drift period (Lagrangian operation) and during the ascent (ascent profile).

After each ascent, ARVOR-DEEP transmits its saved data to the satellites of the Iridium system. The volume of data is reduced using a compression algorithm in order to reduce the time needed for transmission. The Iridium system calculates the float's position during its stay on the sea surface.

This manual describes the ARVOR-DEEP float, how to use it and safety precautions to be observed during handling.

Please read this manual carefully to ensure that ARVOR-DEEP functions as intended.

Overview of the present manual's contents:

- Chapter 2 contains the instructions necessary for the personnel in charge of the deployment
- Chapter 3 describes the components of ARVOR-DEEP; it is intended for those who want a more in-depth understanding of ARVOR-DEEP
- Chapter 4 describes the mission of ARVOR-DEEP
- Chapter 5 describes the various parameters
- Chapter 6 describes the various IRIDIUM messages
- Chapter 7 presents the technical specifications
- Chapter 8 provides explanations about the operation of ARVOR-DEEP
- Chapter 9 specifies the elements of the constraints limited to the transport of Lithium batteries.

## **2 OPERATING INSTRUCTIONS**

The following instructions tell you how to handle, configure, test and launch the ARVOR-DEEP float. Please read these instructions carefully and follow them closely to ensure your ARVOR-DEEP float functions as intended.

### **2.1 Handling Precautions**

ARVOR-DEEP is designed to withstand submersion at great depths for long periods of time (up to five years). This remarkable specification in oceanographic instrumentation is possible thanks to the protection of the casing by coating. This coating is sensitive to impact.

**NOTE:** *Take precautions to preserve the coating during handling. Remove the float from its packing only when absolutely necessary.*

**NOTE:** *Regulations state that ARVOR-DEEP must not be switched on during transport.*

### **2.2 Acceptance Tests**

Immediately upon receipt of the ARVOR-DEEP float, you should test it to confirm that it is complete, correctly configured and has not been damaged in shipment. If your ARVOR-DEEP float fails any of the following tests, you should contact **nke instrumentation**.

#### **2.2.1 Inventory**

The following items should be supplied with your ARVOR-DEEP float:

- The present user manual.
- A test sheet.
- Quickstart & Deployment checklist

**NOTE:** *Disassembly of the float voids the warranty.*

Check that all of the above items are present. If any are missing, contact **nke-instrumentation**.

#### **2.2.2 Physical Inspection**

Upon the opening of the transport casing, visually inspect the float's general condition: Inspect the transport container for dents, damage, signs of impact or other signs that the float has been mishandled during shipping.

Inspect the CTD sensor, antenna, hull, housing around the lower bladder for dents or any other signs of damage

**NOTE:** *Ensure the magnet is in place against the hull (on ON/OFF position), meaning that float is switched OFF.*

### **2.3 Default Parameters**

Notwithstanding special instructions given to NKE during the ARVOR-DEEP preparation stage, the following set of parameters is applied: [section 5](#).

If these parameters are not appropriate, the user can change them himself by following the instructions.

#### **2.3.1 ARGO Identification**

The user is responsible for contacting the AIC in order to obtain the WMO number which will identify the ARVOR-DEEP's mission

#### **2.3.2 Decoding**

The CORIOLIS project team (IFREMER) is able to assist the teams that use ARVOR-DEEP for data processing.

Nke can provide light PC software for manual data decoding. Contact **nke-instrumentation**.

## 2.4 Launching

Following is what you should do to launch the ARVOR-DEEP float.

### 2.4.1 Test the Float and arm the mission

Before you take ARVOR-DEEP on deck for deployment, we recommend that you repeat all of the tests described in [section 2.5.8](#). This will ensure that the float is functioning and configured correctly and maximize the probability of success of your experiment.

**IMPORTANT:** Before launching the float, you must arm the mission by issuing the !AR command:

!AR

ARVOR-DEEP will respond:

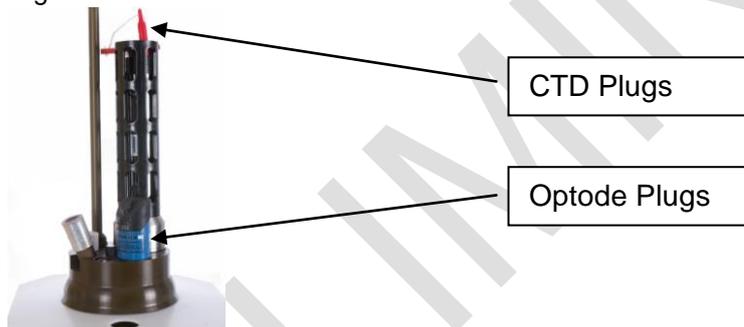
<AR ON>

Put the magnet on the float (ON/OFF position).

**NOTE:** *Once the mission is armed, the next time you will attempt to communicate with the float upon magnet removal, you need to establish Bluetooth connection (see [section 2.5.2](#)) and press "ENTER" within 50 seconds after magnet removal in order to get the prompt ]*.

### 2.4.2 Remove protective plugs and magnet

The pump system of the CTD sensor is sealed by 3 protective plugs. Remove these plugs from the sensor before launching.



**Figure 1 - Sensor plugs to remove**

Remove the magnet located near the top of the float (see Figure 2 - General view of ARVOR DEEP Float). Retain the magnet for future use in case the float is recovered.

ARVOR-DEEP is now ready for launch.

To confirm that the magnet has been removed and that the float is ready for launch, 5 seconds after magnet removal, ARVOR-DEEP starts 5 valves actions. After 80s, the seabird pump is active. If you have water in the CTD, this water goes out by the holes where were the protective plugs. After 100 sec, float starts 5 quick valve activations.

**NOTE:** *Once the magnet has been removed, the ARVOR-DEEP float performs an initial test. Ensure that the CTD pump starts as explained above before placing the float in the water.*

If you do not hear the valve running after 30 seconds, and you do not see the water after 90s, replace the magnet, connect the PC, and conduct the tests described in [section 2.5](#). If these tests fail, contact **nke instrumentation** technical support.

# ARVOR-DEEP FLOAT USER MANUAL

## 2.4.1 Deployment checklist

Test	Description	Expected Result	Result
<b>Check before deployment</b>			
1	Visual inspection	No scratch, good general state	<input type="checkbox"/> OK
2	Magnet Position	Magnet placed on ON/OFF position	<input type="checkbox"/> OK
3	Remove CTD & optode plugs (1 red & 2 white plugs, for CTD, black plug for optode)	Plugs removed (see <a href="#">section 2</a> )	<input type="checkbox"/> OK
4	Distilled Water in conductivity cell	Introduce distilled water in conductivity cell (enable CTD pump check on test 8)	<input type="checkbox"/> OK
<b>Check during deployment</b>			
5	Magnet removal	Magnet removed from ON/OFF position	<input type="checkbox"/> OK
6	5 slow Ev activations	5 Ev activations heard (5-15 sec after magnet removal)	<input type="checkbox"/> OK
8	CTD pump	Water level change in CTD water circuit	<input type="checkbox"/> OK
9	One Minute Delay before mission begins	During 50 sec, user can connect to float with Bluetooth to enter in dialog mode. After this delay, floats begins mission (no more dialog possible with float, until new reset)	<input type="checkbox"/> OK
10	Auto-Test	Full auto-test (int. vacuum, batteries, sensors test, Iridium modem)  Water level change in CTD water circuit	<input type="checkbox"/> OK
<b>11</b>	<b>5 Quick Ev activations</b>	<b>5 Ev activations heard</b>	<input style="border: 1px solid red;" type="checkbox"/> <b>OK</b>
12	Delay before mission	Wait for "Delay Before Mission" Minutes ("PM4" minutes)	<input type="checkbox"/> OK
13	Satellite Transmission	Iridium transmission (files received by mail SBD transmission)	<input type="checkbox"/> OK
<b>Deployment</b>			
14	Deployment	Deployment system in place	<input type="checkbox"/> OK
15	Float drift	Float drift at surface	<input type="checkbox"/> OK

**Table 1 - Deployment Checklist**

If **step 11** is not reached, place magnet on ON/OFF position and try again from beginning.

**Do not DEPLOY after 3 unsuccessful tries !**

### 2.4.2 Launch the Float

**NOTE:** *Keep the float in its protective packaging for as long as possible to guard against any nicks and scratches that could occur during handling. Handle the float carefully, using soft, non-abrasive materials only. Do not lay the float on the deployment vessel's unprotected deck. Use cardboard or cloth to protect it.*

#### 2.4.2.1 *By hand*

ARVOR-DEEP can be launched by hand from the deck from a height of 2 meters

#### 2.4.2.2 *Using a rope*

The damping disk is already fastened on the tube (under the buoyancy foam).

PRELIMINARY

### 2.5 Checks prior to deployment

#### 2.5.1 Necessary Equipment

The equipment required to check that ARVOR-DEEP is functioning correctly and to prepare it for the mission are:

- (1) A PC.  
The most convenient way of communicating with ARVOR-DEEP is with a PC in terminal emulation mode. Among other advantages, this allows storage of configuration parameters and commands. You can use any standard desktop or laptop computer. The PC must be equipped with a serial port (usually called COM1 or COM2).
- (2) VT52 or VT100 terminal emulation software.  
The Hyper Terminal emulation software can be used.
- (3) A Bluetooth Dongle with drivers installed on the PC (BELKIN class 2 model is recommended).
- (4) An accurate time source.  
This could be a wristwatch, a GPS receiver or the PC's internal clock. Some users use a GPS receiver connected to the PC to adjust the clock.

#### 2.5.2 Connecting the PC

Make sure you check the following points before attempting a connection:

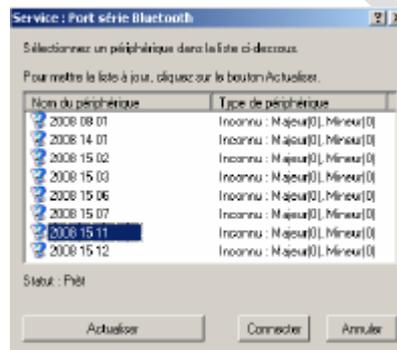
- ✓ Bluetooth key connected to the PC with the drivers installed
- ✓ Magnet present at the Bluetooth's power supply ILS (see Figure 2 - General view of ARVOR DEEP Float)
- ✓ Start Hyperterminal after checking on which COM port the Bluetooth key is installed by going to: Control Panel->System-> click on Hardware tab->Device Manager as shown in the figure below:



- ✓ On the PC, run the following commands as shown in the figure below:
- ✓ Right click on the Bluetooth logo in the bottom right corner of the Desktop
- ✓ Select Quick Connect, Bluetooth Serial Port, then click on other devices



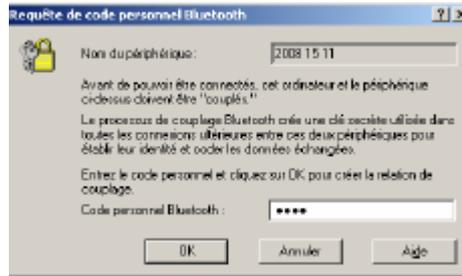
A window appears as shown in the figure below:



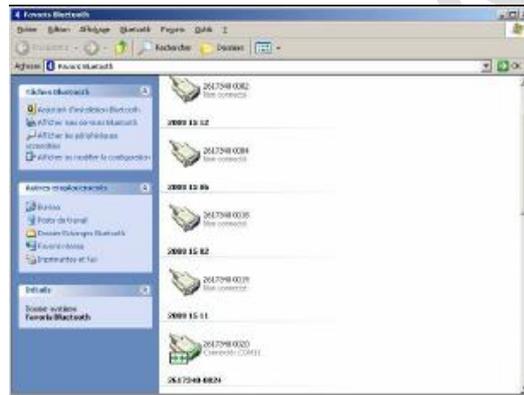
- ✓ Click on Refresh
- ✓ Check that the Bluetooth number is present on the traceability label (see Figure 2 - General view of ARVOR DEEP Float) There are two ways of establishing the connection:
- ✓ Either select the number shown and press Connect
- ✓ Or come back to the previous step and instead of selecting “other devices”, select the number shown
- ✓ When the connection is made, a dialog box appears as shown in the figure above:



Double click on it and a window appears as shown below:



- ✓ Enter the security code "0000"
- ✓ You can now check the connection by double clicking on the Bluetooth logo in bottom right corner of the Desktop
- ✓ The "Bluetooth favourites" window appears:



Use your PC's terminal emulation software to configure the selected serial port for:

- 9,600 baud
- 8 data bits
- 1 stop bit
- Parity: none
- Full duplex
- No flow control

### **2.5.3 Example of Bluetooth dongle tested by NKE**



USB Bluetooth™ adaptor - 100 meters,  
Part # F8T012fr  
Made by Belkin

## 2.5.4 How to Send Commands

You must communicate with ARVOR-DEEP to verify or change its configuration parameters, to read data from the float, or to test the float's functions. You perform these verifications/changes by sending commands, and by observing the float's response to those commands. Compose commands by typing characters on the keyboard of your PC, and send them to ARVOR-DEEP by pressing the Enter key.

In the following descriptions of commands we will use the general syntax:

- Keystrokes entered by the user are written in **bold**.
- Replies received from the float are in normal font.
- Commands entered by the user end with the Enter key.

The software version can be viewed using the **?VL** command

ARVOR-DEEP will respond:

```
<VL 5608Y0x      (where Y indicates Major software revision and x indicates minor software revision)
<VC IRIDIUM>
<AVEC OPTODE>
```

The float's serial number can be viewed using the **?NS** command

ARVOR-DEEP will respond:

```
<NS 14001> (year 14, identification 1)
```

## 2.5.5 How to Read and change Parameter Values

Read the values of "mission commands" by sending the MC command. Do this by typing the characters **?MC** in response to ARVOR-DEEP's ] prompt character then confirm the command by pressing the Enter key. It should look like this:

**?PM**

ARVOR-DEEP will respond:

```
<PM0  255>
<PM1  10>
<PM2   2>
<PM3   6>
<PM4   0>
<PM5   0>
<PM6  12>
<PM7  10>
<PM8 1000>
<PM9 3500>
<PM10 10>
<PM11 200>
<PM12  1>
<PM13 10>
<PM14 25>
<PM15 60>
<PM16  0>
<PM17  1>
```

As you can see, the responses are of the form:

- PM parameter number, value.

You can also read the values of the parameters individually using the command : **?PM X**

where **X** identifies the parameter. Each parameter is identified by a parameter number corresponding to a parameter name. They are summarised for reference in [section 5.1 & 5.2](#)

Parameter no.	Name	Default Value	Units
<b>Mission Parameters</b>			
PM0	Number of Cycles	255	Whole number
PM1	Cycle Period	10	Nb of days
PM2	Reference Day	2	days
PM3	Estimated time at the surface	6	Hours
PM4	Delay Before Mission	0	Minutes
PM5	Descent Sampling Period	0	Seconds
PM6	Drift Sampling Period	12	Hours
PM7	Ascent Sampling Period	10	Seconds
PM8	Drift Depth	1000	dBar
PM9	Profile Depth	3500	dBar
PM10	Threshold surface/Intermediate Pressure	10	dBar
PM11	Threshold Intermediate /bottom Pressure	200	dBar
PM12	Thickness of the surface slices	1	dBar
PM13	Thickness of the intermediate slices	10	dBar
PM14	Thickness of the Bottom slices	25	dBar
PM15	Iridium End Of Life transmission period	60	Minutes
PM16		0	Minutes
PM17	Wait at surface after grounding	1	Minutes

**Table 2 - Mission Parameters**

For example, to verify the value of the ascent sampling period, send the command:

**? PM 7**

ARVOR-DEEP will respond:

<PM7 10>

where 10 is the sampling period in ascent.

The commands for **changing** the values of the mission parameters are of the form:

**!PM X Y**

where X identifies the parameter and Y provides its new value.

For example, to change the number of cycles 200, send the command:

**!PM 0 200**

ARVOR-DEEP will respond:

<PM0 200>

**NOTE:** *ARVOR-DEEP will always respond by confirming the present value of the parameter. This is true even if your attempt to change the parameter's value has been unsuccessful, so you should observe carefully how ARVOR-DEEP responds to your commands.*

### 2.5.6 How to Check and change the Time

Connect the PC to the float using the BT connection (see [section 2.5.2](#)). Ask ARVOR-DEEP to display the time stored in its internal clock by sending the command:

**? TI**

(Do this by typing the characters **? TI** followed by the Enter key). ARVOR-DEEP will respond:

<01/03/14, 14 41 00>

The date and time are in the format DD/MM/YY hh:mm:ss

You can set the time on the float's internal clock by sending the command:

**!TI DD MM YY hh mm ss**

For example, if you send the command:

**!TI 01 03 14 14 30 00**

ARVOR-DEEP will respond:

01/03/14, 14h 30m 00s

### **2.5.7 Configuration Check**

The float has been programmed at the factory. The objective of this portion of the acceptance test is to verify the float's configuration parameters.

Connect the PC to the float (see [section 2.5.2](#)). Send the MC command, as explained in [section 2.5.5.](#), to verify that ARVOR-DEEP's parameters have been set correctly.

All command list is given in Section [User Commands](#) page 25

### **2.5.8 Functional Tests**

Connect the PC to the float (see [section 2.5.2](#)).

**NOTE:** *The hydraulic components will function correctly only if the float is in a vertical position with the antenna up.*

Orient the float vertically, and support it to prevent it from falling over during the performance of the functional tests.

#### **2.5.8.1 Auto-test**

Before sending float auto-test, place the float on vertical position.

These auto-test is used by float to check all internal components.

Standard auto-test can be done by sending command :

**!C**

Float will respond :

<CPU:OK VIDE :OK (600) BAT:OK (14400) CTD\_PowerCtrl:OK CTD\_FastPress:OK SENSOR\_DO:OK IRIDIUM:OK FLASH:OK (3599)>

During auto-test, float will test "internal vacuum", CTD sensor (CTD mode and pressure request), Oxygen sensor (optional), Iridium modem, parameters integrity and firmware integrity (checksum).

#### **2.5.8.2 Display of technological parameters**

This command is used to display :

- Internal vacuum (V).  
This vacuum is drawn on the float as one of the final steps of assembly. It should be between 500 and 700 mbar absolute. 600 mbar (@20°C) is recommended.
- Battery voltage (B)  
Normal values for a new battery are 14.4 volts (see test sheets for limits).  
Send the command :

**?VB**

ARVOR-DEEP will respond:

<B:145 V:605 (A=2.000 B=200.000)> meaning 14.5V for battery voltage and 605 mBars as internal vacuum

### 2.5.8.3 Display Sensor Data

This command is used to display:

- External pressure (P)
- Temperature (T)
- Salinity (S)

Send the command:

**?S**

ARVOR-DEEP will respond:

<S: 10cBars 24561mdc 12mPSU>

As this sensor is in open air, only the temperature data should be regarded as accurate.

### 2.5.8.4 Test Hydraulic Pump

To activate the pump for one second, send the command :

**!P 100**

Listen for the pump running for one second (unit: centiseconds).

### 2.5.8.5 Test Hydraulic Valve

To activate the valve for one second, send the command:

**!E 100**

Listen for the actuation of the valve (unit: centiseconds).

### 2.5.8.6 Test Iridium/GPS Subsystem

To test the Iridium transmitter, send the command :

**!SE**

The float will time with GPS, then will send a technical SBD message. Put the magnet back in place to stop the transmission.

This command will cause ARVOR-DEEP to transmit one technical message. The format of which is described in [section 6](#). Use your email address to check transmission was OK. The message content is not meaningful, this is a test of the transmission only.

### 2.5.8.7 Test armed mode

To check if armed mode is ON or OFF, send the command :

**?AR**

Float will respond :

<AR ON> if armed mode is ON or <AR OFF> if armed mode is OFF.

Armed mode set "ON" means that float is ready for deployment. Armed mode set to OFF means that float enters in "user-dialog mode" each time float is powered ON.

You have now completed the functional tests. Ensure the magnet is in place on the ON/OFF position (see Figure 3 - Magnet positions).

## **Before deployment, armed mode must absolutely be setted to ON !**

If armed mode is ON, next time float is powered ON, after a delay of 50 seconds, float begin a new mission and it won't be possible to send command to float anymore. During the 50s delay, user can enter in "dialog mode" by connecting on bluetooth and type on "ENTER" until float send prompt character ( "**]**" ).

Armed mode is set in factory on request. This information (AR state) can also be verify by reading FIT file delivered with float.

You have now completed the functional tests. Ensure the magnet is in place on the ON/OFF position (see Figure 3 - Magnet positions).

### 3 GENERAL DESCRIPTION OF ARVOR-DEEP FLOAT

#### 3.1 ARVOR-DEEP

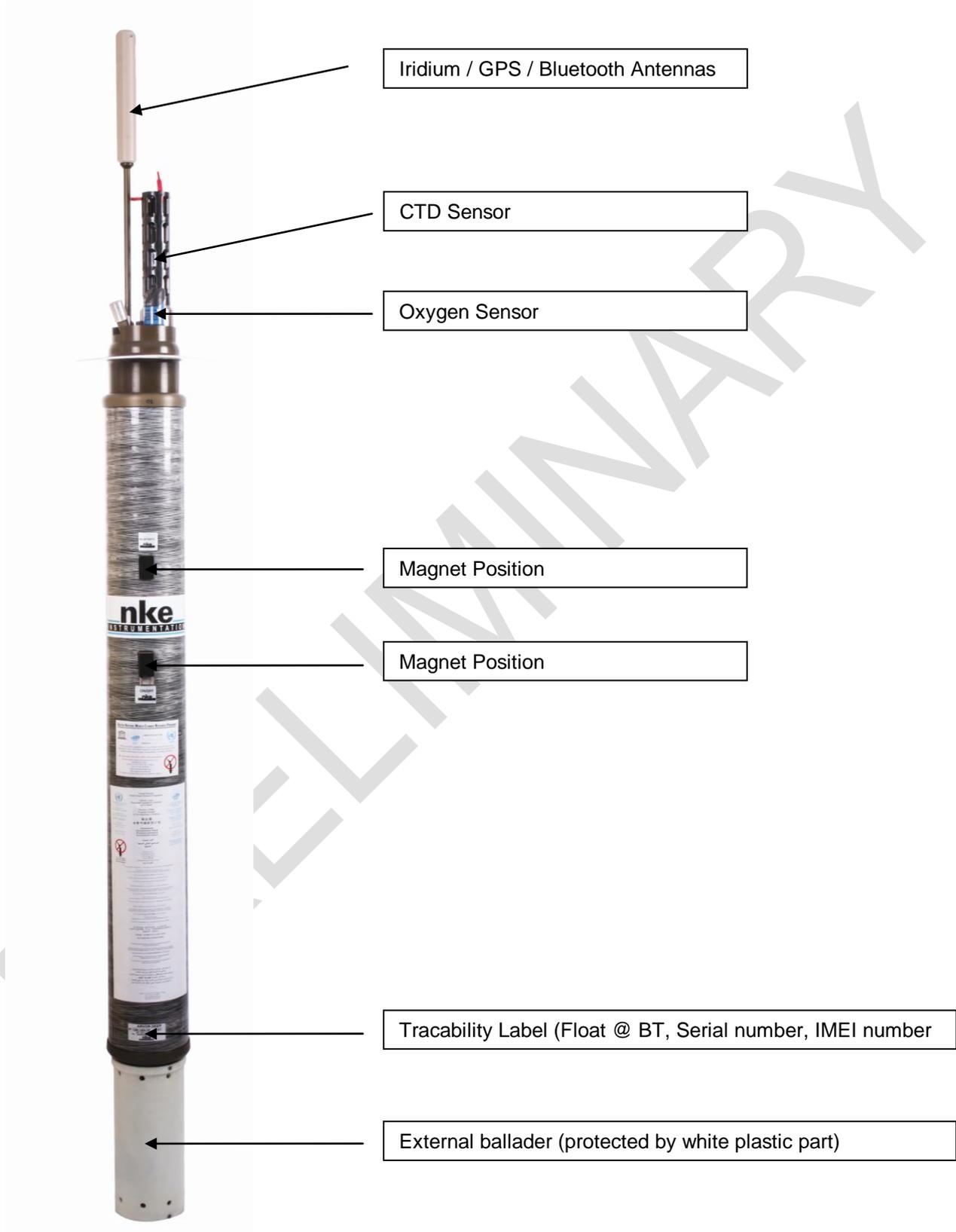
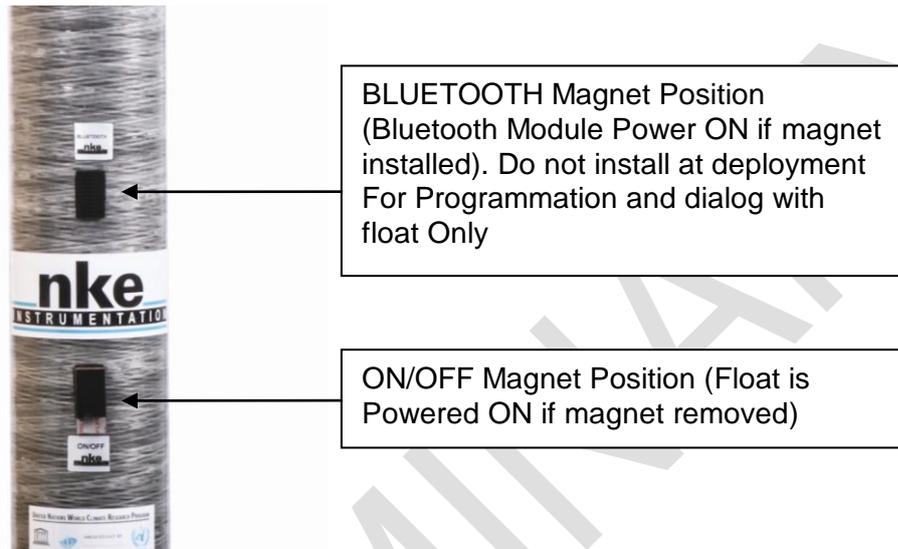


Figure 2 - General view of ARVOR DEEP Float

### 3.2 Hull

The ARVOR-DEEP float is encased in a cylinder measuring 11.3 cm in diameter and 100 cm in height. A surface finish prolongs life by impeding corrosion. The float is carefully designed to have a compressibility that is lower than that of seawater, essential for stable operation at ocean depths where pressures reach 410 atmospheres.

### 3.3 Magnet Positions



**Figure 3 - Magnet positions**

### 3.4 Density Control System

Descent and ascent depend upon buoyancy. ARVOR-DEEP is balanced when its density is equal to that of the level of surrounding water. The float has a fixed mass. A precision hydraulic system is used to adjust its volume. This system inflates or deflates an external bladder by exchanging oil with an internal reservoir. This exchange is performed by a hydraulic system comprising a high-pressure pump and a solenoid valve.

The interested reader is referred to a more detailed description of the operation of ARVOR-DEEP's density control system in [section 8](#).

### 3.5 Sensors

ARVOR-DEEP is equipped with precision instruments for measuring :

- pressure, temperature and salinity with the SEABIRD SBE41CP CTD sensor. Specifications of the sensor are provided in [sections 7](#).

Optional sensors :

- Dissolved Oxygen with the Oxygen Optode AANDERAA 3830 or 4330 sensor

### 3.6 Iridium/GPS modem

While the float is at the surface, the Iridium Modem sends stored data to the satellites of the Iridium system (see [sections 6. and 6.1.](#)). The transmitter has a unique IMEI ID. This ID identifies the individual float. The antenna is mounted on the top end of the ARVOR-DEEP float and must be above the sea surface in order for transmissions to reach the satellites.

### **3.7 CPU Board**

This board contains a micro-controller (or CPU) that controls ARVOR-DEEP. Its functions include maintenance of the calendar and internal clock, supervision of the depth cycling process, data processing and activation and control of the hydraulics.

This board allows communication with the outside world for the purpose of testing and programming.

### **3.8 Battery**

A battery of lithium thionyl chloride cells supplies the energy required to operate ARVOR-DEEP.

### **3.9 MMI link**

The User link is made via Bluetooth (radiofrequency link)

## **4 THE LIFE OF AN ARVOR-DEEP FLOAT**

The life of an ARVOR-DEEP float is divided into 4 phases: Storage/Transport, Deployment, Mission & Life Expiry.

#### **(1) Storage/Transport**

During this phase, the float, packed in its transport case, awaits deployment. The electronic components are dormant, and float's buoyancy control functions are completely shut down. This is the appropriate status for both transport and storage.

#### **(2) Deployment**

The float is removed from its protective packaging, configured, tested and launched at sea.

#### **(3) Mission**

The mission begins with the launching of the float. During the Mission, ARVOR-DEEP conducts a pre-programmed number of cycles of descent, submerged drift, ascent and data transmission. During these cycles it collects CTD data, computes data, and transmits it to the Iridium satellite system.

#### **(4) Life Expiry**

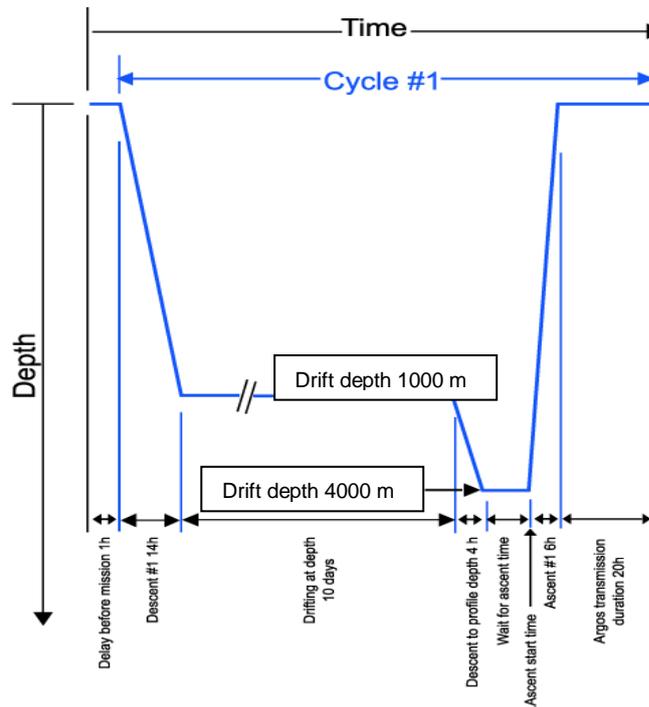
Life Expiry begins automatically upon completion of the pre-programmed number of cycles. During Life Expiry, the float, drifting on the sea surface, periodically transmits messages until the battery is depleted. Reception of these messages makes it possible to locate the float, to follow its movements and, if desired, to recover it.

If the battery is depleted before completion of the pre-programmed number of cycles, ARVOR-DEEP will probably remain submerged and cannot be located or recovered.

### **4.1 The Mission - Overview**

We call "Mission" the period between the moment when the float is launched at the experiment zone and the moment when the data transmission relating to the final depth cycle is completed.

During the Mission, ARVOR-DEEP conducts ascent and descent profiles, separated by periods of Iridium transmitting and drifting at a predetermined depth. ARVOR-DEEP can collect data during the descent, submerged drift, or ascent portions of the cycle, and transmits the collected data during the surface drift period at the end of each cycle. One cycle is shown in the figure below.



**Figure 4 Schematic representation of a ARVOR-DEEP's depth-cycle during the Mission**

**(1) Delay Before Mission**

To prevent ARVOR-DEEP from trying to sink before it is in the water, the float waits for this time before starting its descent. This happens only before the first cycle; it is not repeated at each cycle.

**(2) IRIDIUM/GPS Preliminary Transmissions**

To test Iridium transmitter, before descent phase, float will perform Iridium transmission by sending a technical message. A GPS position will be acquire and transmit in technical message.

**(3) "Pressure sensor offset" reset**

Resetoffset command is send to SBE41-CP sensor -> Sample pressure for 1 minute. Store measured pressure as new pressure offset. Maximum allowed offset is 2 percent of full scale.

**(4) Buoyancy reduction**

Float is deployed with full external bladder to get a maximal buoyancy. To reach neutral buoyancy position before descending, float needs to transfer oil inside float. For the 2 first cycles this phase can take up to one hour and a half (by opening electro-valve several times with one minute for pressure monitoring between activations). At following cycles, float memorized necessary global electro-valve opening time (precedent cycle) and reduce this global duration by reduce time between valve activations to 1 second instead of 1 min.

**(5) Descent**

The float descends at an average speed of 3 cm/sec. During descent, which typically lasts a few hours, ARVOR-DEEP can detect possible grounding on a high portion of the seabed and can move away from such places (see [section 4.3.](#) for more details on grounding). ARVOR-DEEP can collect CTD measurements during descent or ascent. In order to respect the requirement of the ARGO program, the first cycle of the mission collect CTD measurements during the descent at the sampling period of 10 seconds.

**(6) Drifting at Depth**

During the drift period, ARVOR-DEEP drifts underwater at a user-selected drift depth, typically 1,000m to 2,000m below the sea surface. The drift period is user-selectable and can last from a few days to several weeks, but is typically 10 days. The float automatically adjusts its buoyancy if it drifts from the selected depth by more than 5 bars over a 60-minute period. ARVOR-DEEP can collect CTD measurements at user-selected intervals during this drift period if the user selects this option.

**(7) Descent to Profile Depth**

The user may select a starting depth for the ascent profile that is deeper than the drift depth. If this is the case, ARVOR-DEEP must first descend to the profile depth before beginning the ascent profile. ARVOR-DEEP can detect a possible grounding during this descent and take corrective action (as described in [section 4.3.](#))

### (8) Wait for Ascent Time

The user can program several floats to conduct profiles simultaneously. This makes it possible to use several ARVOR-DEEP floats in a network of synoptic measurements, even though the instruments are not all deployed at the same time. If this is the case, it may be necessary for ARVOR-DEEP to standby at the profile starting depth while awaiting the scheduled ascent time.

### (9) Ascent

Ascent lasts a few hours, during which time ARVOR-DEEP ascends to the sea surface at an average speed of 10cm/sec. ARVOR-DEEP can collect CTD measurements during descent or ascent.

### (10) Transmission

At the end of each cycle, the float finds sufficient buoyancy to ensure Iridium transmission quality. ARVOR-DEEP remains at the sea surface transmitting the data collected during the preceding descent-drift- ascent portion of the cycle.

## 4.2 Descent

While the float is still at the sea surface ARVOR-DEEP measures and records its pressure sensor offset. This offset is used to correct all pressure measurements. The offset is transmitted in a technical message (see [section 6.](#)) for a description of technical messages format). Descent takes the float from the sea surface to the drift depth. Initially, in order to avoid possible collisions with ships, ARVOR-DEEP's objective is to lose buoyancy in the shortest possible time. It does this by opening the solenoid valve for a time period that is initially long, but decreases as the float approaches its target depth.

If the user chooses, ARVOR-DEEP will collect CTD measurements during descent and/or during ascent. The interval between CTD measurements is user-programmable.

## 4.3 Grounding

ARVOR-DEEP monitors itself for possible grounding on the seabed. During descent to drift depth, if the pressure remains unchanged for too long, ARVOR-DEEP enters a correction mode. The user selects one of two available modes during Mission programming before launch (Technical parameter PT 10) :

- Grounding Mode = 0: The pre-programmed drift depth is disregarded. The pressure at the time of grounding minus an offset (100 dBar typical) is taken as the new value for the drift pressure. The float adjusts its buoyancy to reach this new drift depth. The drift depth reverts to its programmed value for subsequent cycles.

If the grounded pressure is lower than a programmed threshold (200 dBar), the float remains on the seabed until the next programmed ascent time.

- Grounding Mode = 1: the float remains where it is until the next scheduled ascent time. The pressure measured at grounding becomes the profile start pressure for the cycle in progress. The profile start pressure reverts to its programmed value for subsequent cycles.

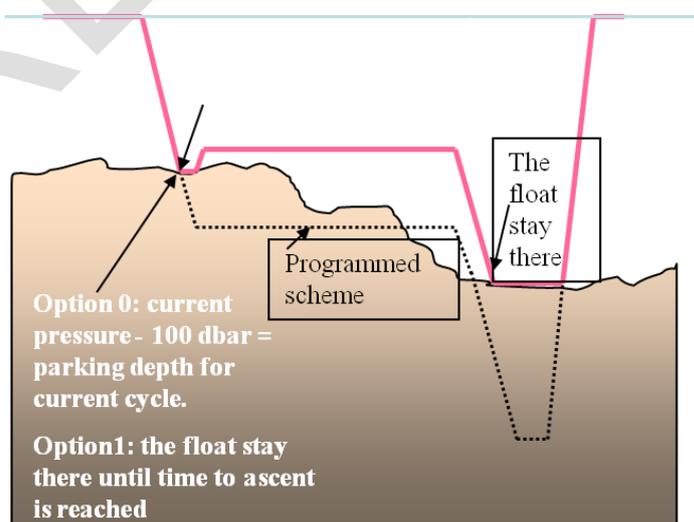


Figure 5 - Schematic representation of a ARVOR-DEEP's behaviour in case of grounding

### 4.4 Submerged Drift

While ARVOR-DEEP is drifting at drift depth, it checks the external pressure every 30 minutes to determine whether there is need either for depth adjustment or for an emergency ascent.

If the measured pressure differs from the drift depth pressure by more than a specified tolerance, and this difference is maintained, ARVOR-DEEP adjusts its buoyancy to return to the drift depth.

If the pressure increases by an amount that exceeds a factory-set danger threshold, ARVOR-DEEP immediately ascends to the sea surface.

If the user chooses, ARVOR-DEEP will collect CTD measurements at user-selected intervals during submerged drift.

### 4.5 Ascent

If the chosen ascent profile starting pressure is higher than the drift pressure, the float must first descend to reach the profile starting pressure.

If grounding is detected while ARVOR-DEEP is descending to the profile starting pressure, the present pressure is substituted for the profile starting pressure. This substitution is only for the cycle in progress; the profile starting pressure reverts to its pre-programmed value for subsequent cycles.

Once the profile starting pressure has been reached, the float waits for the programmed time to begin the ascent. If this time is reached before the float has arrived at the profile starting pressure, the ascent starts immediately.

ARVOR-DEEP ascends by repeated use of the pump. When the pressure change between two successive measurements is less than 1 bar, the pump is activated for a pre-set time period. In this way, the pump performs minimum work at high pressure, which ensures minimum electrical energy consumption. The average speed of ascent is approximately 10cm/sec. For a 4,000m profile, the ascent would therefore last 12 hours.

When the pressure drops below 10 dBar (signifying completion of ascent), ARVOR-DEEP waits 10 minutes and then activates the pump in order to empty the reservoir and achieve maximum buoyancy. If the user chooses, ARVOR-DEEP will collect CTD measurements during descent and/or ascent. CTD measurements begin at the profile start time and stop 10 minutes after the float rises above the 10 dBar isobar in its approach to the sea surface. The interval between CTD measurements is user-programmable. For example, during a profile beginning at 4,000 m with a 10 sec sampling period, 4300 CTD measurements will be collected.

### 4.6 Transmission

The data transmission process takes into account the limitations of the Iridium data collection system, including:

- the uncertainty of the float's antenna emerging in rough seas;
- radio propagation uncertainties due to weather conditions, and;
- the satellites' operational status.

ARVOR-DEEP creates transmission messages from the stored "Treated data" (see [section 6.10](#) for treatment details). The transmission of all messages is repeated until the total duration of transmissions exceeds the user-programmed minimum duration. The interval between transmissions is also user-programmable.

Please refer to [section 6](#) for a detailed description of the transmitted message formats.

### 5 ARVOR-DEEP PARAMETERS

ARVOR-DEEP's configuration is determined by the values of its mission parameters defined below. Instructions on how to read and change the values of these parameters are provided in [sections 2.5.5](#). The following table summarizes all parameter names, ranges and default values (Software YLA5608Y0x).

Parameter no.	Name	Default Value	Units
<b>Mission Parameters</b>			
PM0	Number of Cycles	255	Whole number
PM1	Cycle Period	10	Nb of days
PM2	Reference Day	2	Hours
PM3	Estimated time at the surface	6	Hours
PM4	Delay Before Mission	0	Minutes
PM5	Descent Sampling Period	0	Seconds
PM6	Drift Sampling Period	12	Hours
PM7	Ascent Sampling Period	10	Seconds
PM8	Drift Depth	1000	dbars
PM9	Profile Depth	4000	dbars
PM10	Threshold surface/Intermediate Pressure	10	dbars
PM11	Threshold Intermediate /bottom Pressure	200	dbars
PM12	Thickness of the surface slices	1	dbars
PM13	Thickness of the intermediate slices	10	dbars
PM14	Thickness of the Bottom slices	25	dbars
PM15	Iridium End Of Life transmission period	60	Minutes
PM16	Iridium 2 <sup>nd</sup> session waiting time ("0" means no 2 <sup>nd</sup> session)	0	Minutes
PM17	Wait at surface after grounding	1	Minutes

**Table 3 - Summary of ARVOR-DEEP user-programmable parameters**

#### 5.1 Mission Parameters

##### **PM(0) Total Number of Cycles**

This is the total number of cycles of descent, submerged drift, ascent and transmission that ARVOR-DEEP perform. The mission ends and ARVOR-DEEP enters Life Expiry mode when this number of cycles has been completed.

The capacity of ARVOR-DEEP's batteries is sufficient for at least 150 cycles. If you wish to recover ARVOR-DEEP at the end of the mission, you must set the number of cycles at less than 150 to ensure there is sufficient battery capacity remaining to allow ARVOR-DEEP to return to the sea surface and enter Life Expiry.

Under favourable conditions, the battery capacity may exceed 150 cycles. If you do not plan to recover the ARVOR-DEEP float, you may choose to set the number of cycles to 150 to ensure that ARVOR-DEEP completes the maximum number of cycles possible.

##### **PM(1) Cycle Period (days)**

The duration of one cycle of descent, submerged drift, ascent and transmission. ARVOR-DEEP waits submerged at the drift depth for as long as necessary to make the cycle the selected duration.

##### **PM(2) Reference Day (number of days)**

Allows you to configure a group of floats so that they all conduct their profiles at the same time. The parameter defines a particular day on which the first profile is to be made. When the float's internal clock's day number equals the reference day, it will conduct its first profile. The float's internal clock day number is set to zero when the mission starts. When setting the reference day, it is recommended to allow enough time between the deployment and reach of profiling depth. Using a reference day of at least 2 will ensure the first profile is complete.

**PM(3) Estimated Time on Surface (hours)**

Estimated time float must reach surface.

**PM(4) Delay Before Mission (minutes)**

To prevent ARVOR-DEEP from trying to sink while still on deck, the float waits for this time before commanding the buoyancy engine to start the descent. After disconnection of the PC, followed by removal of the magnet, ARVOR-DEEP will wait for this delay before beginning the descent. The delay is measured after the first start of the pump which confirms the removal of the magnet (see [section 2.4.1](#)) and before the start of the descent.

**PM(5) Descent Sampling Period (seconds)**

The time interval between successive CTD measurements during descent. If this parameter is set to 0 seconds, no profile will be carried out during the descent phase. Nevertheless, due to the ARGO requirements, the first descent profile of the mission is automatically done even if the parameter was equal to 0.

**PM(6) Drift Sampling Period (hours)**

The time interval between successive CTD measurements during ARVOR-DEEP's stay at the drift depth.

**PM(7) Ascent Sampling Period (seconds)**

The time interval between successive CTD measurements during ascent.

**PM(8) Drift Depth (dbar) \*\***

The depth at which ARVOR-DEEP drifts after completion of a descent while awaiting the time scheduled for the beginning of the next ascent.

**PM(9) Profile Depth \*\***

Depth at which profiling begins if in an ascending profile. If ARVOR-DEEP is drifting at some shallower depth, it will first descend to the profile depth before starting the ascent profile.

**PM(10) Threshold surface/Intermediate Pressure (dbar) \*\***

The isobar that divides surface depths from intermediate depths for the purpose of data reduction.

**PM(11) Threshold Intermediate / Bottom Pressure (dbar) \*\***

The isobar that divides Intermediate depths from shallow depths for the purpose of data reduction.

**PM(12) Thickness of the surface slices (dbar) \*\***

Thickness of the slices for shallow depths (algorithm of data reduction).

**PM(13) Thickness of the intermediate slices (dbar) \*\***

Thickness of the slices for shallow depths (algorithm of data reduction).

**PM(14) Thickness of the bottom slices (dbar) \*\***

Thickness of the slices for deep depths (algorithm of data reduction).

**PM(15) End of life period (hours)**

Transmission period (in hours) once float is in "end of life mode" (all programmed cycles have been reached. Float send Technical SBD message.

**PM(16) 2<sup>nd</sup> Iridium Session Wait Period (min)**

At beginning of cycle, if this parameter is different of zero, 2 SBD sessions will occur. This enable to check if a change on mission or technical parameter has been correctly treated by float and if new parameters are effective for next cycle. After the 1<sup>st</sup> transmission, float will wait for PM16 minutes before proceeding to 2<sup>nd</sup> transmission.

# ARVOR-DEEP FLOAT

## USER MANUAL

### PM(17) Delay in case of grounding at surface (minutes)

Transmission period (in hours) once float is in “end of life mode” (all programmed cycles have been reached. Float send Technical messages.

\*\* ARVOR-DEEP can transmit up to 1000 samples per cycle. Theoretical number of samples to be acquired can be estimated based on different threshold between 3 zones and on slices thickness.

## 5.2 User Commands

Command	Rôle
!C	Float auto-test.
?CK	Firmware checksum check
!SE	Initiate Iridium transmission session
!PM x y	Set value y for “Parameter mission” x
?PM	Screen all mission parameters
?PM x	Screen mission parameter x
!PT x y *	Set value y for “technical parameter” x
?PT *	Screen all technical parameters
?PT x *	Screen technical parameter x
!SH	Activate or de-activate Show mode <b>MUST BE OFF FOR DEPLOYMENT</b>
?SH	Request show mode state
!TI jj mm aa hh mn ss	Set date and time to dd/mm/yy hh H : mn M : ss S
?TI	Request float’s internal date and time
?DH	Read all hydraulic data (pump and electrovalve activations)
?DT ALL x	Read all Treated Data for sensor x
?DB	Read all Raw Data for sensor x
!E x	Activate electrovalve for x cs (ctrl-c to stop)
!P x	Activate pump for x cs (ctrl-c to stop)
?S	CTD sensor acquisition
?FP	Fast Pressure request
?VB	Request internal vacuum and battery voltage (in decivolt and milliBars)
!AR	Arm float or deactivate arm mode <b>MUST BE ON FOR DEPLOYMENT</b>
?AR	Request arm state
!RP	Parameters are transferred from EEPROM memory to RAM memory
?VL	Request software version
?NS	Request float’s serial number

# ARVOR-DEEP FLOAT

## USER MANUAL

!K x	Command to activate or deactivate read/Write access for technical parameters. X value is communicated to users upon request to nke
?RE	Read the 5 last reset date and time
!PB	Request Battery Voltage with hydraulic pump active

**Table 4 - User command list**

\* : protected command (need !K x to unlock)

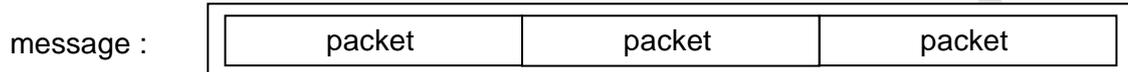
PRELIMINARY

## 6 IRIDIUM FORMATS

### 6.1 Overview

The data transmission process begins as soon as an ascent profile is completed. It starts with reduction of the data. ARVOR-DEEP then formats and transmits the message. The reduction of data processing consists in storing the significant points of the CTD triplets arithmetic mean with the layer format.

SBD message contains up to 3 packets (300 bytes max). One packet have a 100 bytes size



Ten types of packets are generated according to the content of the data frame:

Packet type number	Message Type
0	Technical message n°1
1	Descent CTD message
2	Drift CTD message
3	Ascent CTD message
4	Technical message n°2
5	Programmation Message
6	Hydraulic valve message
7	Hydraulic pump message
8	Descent CTDO message
9	Drift CTDO message
10	Ascent CTDO message



**300 bytes message N°1 sent**

**300 bytes message N°2 sent**

**300 bytes message N°n sent**

The three types of CTD messages and 3 types of CTDO messages all contain recorded physical measurements. The technical messages contains data regarding the configuration and functioning of the float and its buoyancy control mechanism.

The message type is formed from bits 1 to 4 of the data frame. The formatting of the data frame for each message type is described in the pages that follow.

### 6.2 Technical message 1 (type =0)

Data	Format (bytes)	Resolution
Type (= 0)	1	
<b>General informations</b>		
Cycle number	2	
<b>Emergence reduction</b>		
Day of beginning	1	1 day
Month of beginning	1	1 month
Year of beginning	1	1 year
Relative start day (to mission's beginning)	2	
Cycle start time	2	1 min
Hydraulic action	2	1 action
number of valve actions at the surface	1	1 action
Grounded at surface	1	0 = no, 1 = yes
<b>Parking depth descent</b>		
descent start time	2	1 min
float stabilisation time	2	1 min
end of descent time	2	1 min
number of valve actions in descent	1	1 action
number of pump actions in descent	1	1 action
float stabilisation pressure	2	1 dBar
Max pressure during descent to parking depth	2	1 dBar
<b>Parking drift Phase</b>		
Beginning drift phase Absolute day	1	1 day
number of entrance in drift target range (descent)	1	
number of repositions	1	
minimum pressure in drift to parking depth	2	1 dBar
maximum pressure in drift to parking depth	2	1 dBar
number of valve actions in parking	1	1 action
number of pump actions in parking	1	1 action
<b>Descent to Profile depth</b>		
descent start time	2	1 min
end of descent time	2	1 min
number of valve actions in descent	1	1 action
number of pump actions in descent	1	1 action
max pressure in descent to Pprofile	2	1 dBar
<b>Drift to P Profile Phase</b>		
number of entrance in drift target range	1	
number of re-positioning in profile stand-by	1	
number of valve actions in drift to Profile	1	
number of pump actions in drift to Profile	1	
minimum pressure in drift to Pprofile	2	1 dBar
maximum pressure in drift to Pprofile	2	1 dBar
<b>Ascent Phase</b>		

Ascent start time	2	1 min
time at end of ascent (hh+mm+ss)	2	1 min
number of pump actions in ascent	1	1 action
<b>General information</b>		
Float's time (hh+mm+ss)	3	1h, 1min, 1sec (1 byte each)
Float's date (dd+mm+yy)	3	1day, 1month, 1year, 1byte each
pressure sensor offset (two's complement coded)	1	1 cBar
internal pressure	1	5 mBar
batteries voltage drop at Pmax, pump ON (with regard to Unom = 15.0 V) (in dV)	1	0.1 V
RTC state indicator ( normal = 0, failure = 1)	1	
Coherence problem counter	1	
oxygen sensor Status (0 = normal, 1 = failure)	1	
<b>GPS Data</b>		
GPS latitude in degrees	1	1 degree
GPS latitude in minutes	1	1 minute
GPS latitude in minutes fractions (4 <sup>th</sup> )	2	1 minute fraction (4 <sup>th</sup> )
GPS latitude orientation (0= North, 1 = South)	1	
GPS longitude in degrees	1	1 degree
GPS longitude in minutes	1	1 minute
GPS longitude in minutes fractions (4 <sup>th</sup> )	2	1 minute fraction (4 <sup>th</sup> )
GPS longitude orientation (0= East, 1 = West)	1	
GPS valid fix (1 = valid, 0 = not valid)	1	
GPS session duration	2	1 second
GPS retries	1	
<b>Iridium remote control</b>		
Nb of Remote control received	1	
Nb of Remote control rejected	1	
<b>End Of Life information</b>		
End Of Life detection flag	1	1 = End Of life
End Of life Start hour	3	1h, 1min, 1sec (1 byte each)
End Of life Start Date	3	1day, 1month, 1year, 1byte each
<b>Previous transmission information</b>		
Previous Iridium transmission duration	2	1 sec
Number of SBD session for reception	1	
Number of SBD session for transmission	2	
Not used (filled by zeros)	4	
<b>Total</b>	<b>100</b>	

**Table 5 - Technical message n°1**

### 6.3 Technical message 2 (type = 4)

Data	Nb bytes	Res
Type (=4)	1	
<b>Data Information</b>		
number of descent CTD messages	1	1 packet
number of drift CTD messages	1	1 packet
number of ascent CTD messages	1	1 packet
number of descent slices in shallow zone	2	
number of descent slices in deep zone	2	
number of CTD measurements in drift	1	
number of ascent slices in shallow zone	2	
number of ascent slices in deep zone	2	
<b>Sub-surface Point</b>		
Sub-Surface pressure	2	1 cBar
Sub-Surface temperature	2	1 m°C
Sub-Surface salinity	2	1mPSU
Sub-surface C1PHASE	2	0,002°
Sub-surface C2PHASE	2	0,002°
Sub-surface Optode Temperature	2	1 m°C
<b>Grounding</b>		
Grounding number	1	
1st Grounding pressure	2	1 dBar
1 <sup>st</sup> Grounding day relative to cycle beginning	1	1 day
Hour at 1 <sup>st</sup> grounding	2	1 min
1st grounding phase	1	ER:2, DescPd:3, Parkdrift:4, descPp:5, driftPp=6
number of ev activations before 1 <sup>st</sup> grounding detection	1	
2 <sup>nd</sup> Grounding pressure	2	1 dBar
2 <sup>nd</sup> Grounding day relative to cycle beginning	1	1 day
Hour at 2 <sup>nd</sup> grounding	2	1 min
2 <sup>nd</sup> grounding phase	1	ER:2, DescPd:3, drift:4, descPp:5, driftPp=6
number of ev activations before 2 <sup>nd</sup> grounding detection	1	
<b>Emergency ascent</b>		
Emergency ascent number	1	
1 <sup>st</sup> Emergency ascent time	2	1 min
1 <sup>st</sup> Emergency pressure	2	1 dBar
number of pump actions in emergency ascent	1	

1 <sup>st</sup> Emergency ascent relative day (to 1 <sup>st</sup> cycle day)	1	1 day
<b>Various</b>		
Pump actions before float begins ascent	1	
Speed at grounding detection	1	1 cm / s
Internal vacuum at ascent start-up	1	5 mbars
Last reset Hour : HH	3	1 sec
MM		
SS		
Last reset date : JJ	3	
MM		
AA		
<b>Complement</b>		
Complement (filled by zeros)	44	
<b>TOTAL</b>	<b>100</b>	<b>bytes</b>

Table 6 - Technical message n°2

PRELIMINARY

### 6.4 Descent Profile CTD Message (type = 1)

Data	Format	Resolution
Type (=1)	1	1
Relative day	4	
Hour (hh) (2 bytes)		1 hour
Minute(mm) (1 byte)		1 min
Seconds (ss) (1 byte)		1 sec
<b>1st CTD sample</b>		
Pressure	2	0.1 dBar
temperature	2	0.001°C
Salinity	2	1 mPSU
<b>2nd CTD sample</b>		
Pressure	2	0.1 dBar
temperature	2	1 m°C
Salinity	2	1 mPSU
<b>3rd CTD sample</b>		
...	...	
<b>15th CTD sample</b>		
Pressure	2	0.1 dBar
Temperature	2	1 m°C
Salinity	2	1 mPSU
<b>complement</b>		
Complement	5	
<b>TOTAL</b>	<b>100</b>	

- Relative day (1<sup>st</sup> sample of message) : 2 bytes for Day and hour (coded in hours), 1 byte for minutes, 1 byte for seconds
- Pressure is coded in two's complement (in cBars) with an offset of 10000 cBars
- Temperature is coded in two's complement (in m°C)
- Salinity is code in mPSU

Table 7 - Descent CTD message

### 6.5 Submerged Drift CTD Message (type = 2)

Identical to Descent profile CTD message with **type 2**

### 6.6 Ascent profile CTD Message (type = 3)

Identical to Descent profile CTD message with **type 3**

### 6.7 Descent Profile CTDO Message (type = 8)

Data	Format	Resolution
Type (=1)	1	1
Relative day	4	
Hour (hh) (2 bytes)		1 hour
Minute(mm) (1 byte)		1 min
Seconds (ss) (1 byte)		1 sec
<b>1st CTD sample</b>		
Pressure	2	0.1 dBar
temperature	2	0.001°C
Salinity	2	1 mPSU
C1Ph	2	0.002°
C2Ph	2	0.002°
Optode Temp	2	0.001°C
<b>2<sup>nd</sup> CTD sample</b>		
...	...	
<b>7th CTD sample</b>		
Pressure	2	0.1 dBar
Temperature	2	1 m°C
Salinity	2	1 mPSU
C1Ph	2	0.002°
C2Ph	2	0.002°
Optode Temp	2	0.001°C
<b>complement</b>		
Complement	11	
<b>TOTAL</b>	<b>100</b>	

- Relative day (1<sup>st</sup> sample of message) : 2 bytes for Day and hour (coded in hours), 1 byte for minutes, 1 byte for seconds
- Pressure is coded in two's complement (in cBars) with an offset of 10000 cBars
- Temperature is coded in two's complement (in m°C)
- Salinity is code in mPSU
- Phases C1Ph and C2Ph are coded with a 0.002° resolution and an offset of 40°
- Optode temperature is coded in m°C with an offset of 5000 m°C

Table 8 - Descent CTDO message

### 6.8 Submerged Drift CTD Message (type = 9)

Identical to Descent profile CTD message with **type 9**

### 6.9 Ascent profile CTD Message (type = 10)

Identical to Descent profile CTD message with **type 10**

### 6.10 CTD Data Treatment details

Before transmission, all data have to be treated. Depending on sampling period, number of acquired raw data per profile could be too high for good Transmission. So raw data are treated with following strategy : Operation to convert raw data (CTD or CTDO samples) to “treated data” (CTD or CTDO data to transmit) consist in 2 successive operations to raw data : **Decimation & averaging** depending on **zone & Slice thickness**

#### 6.10.1 Zone & Slice thickness

User can define 3 zones with Threshold & Specific Slice Thickness (Mission commands).

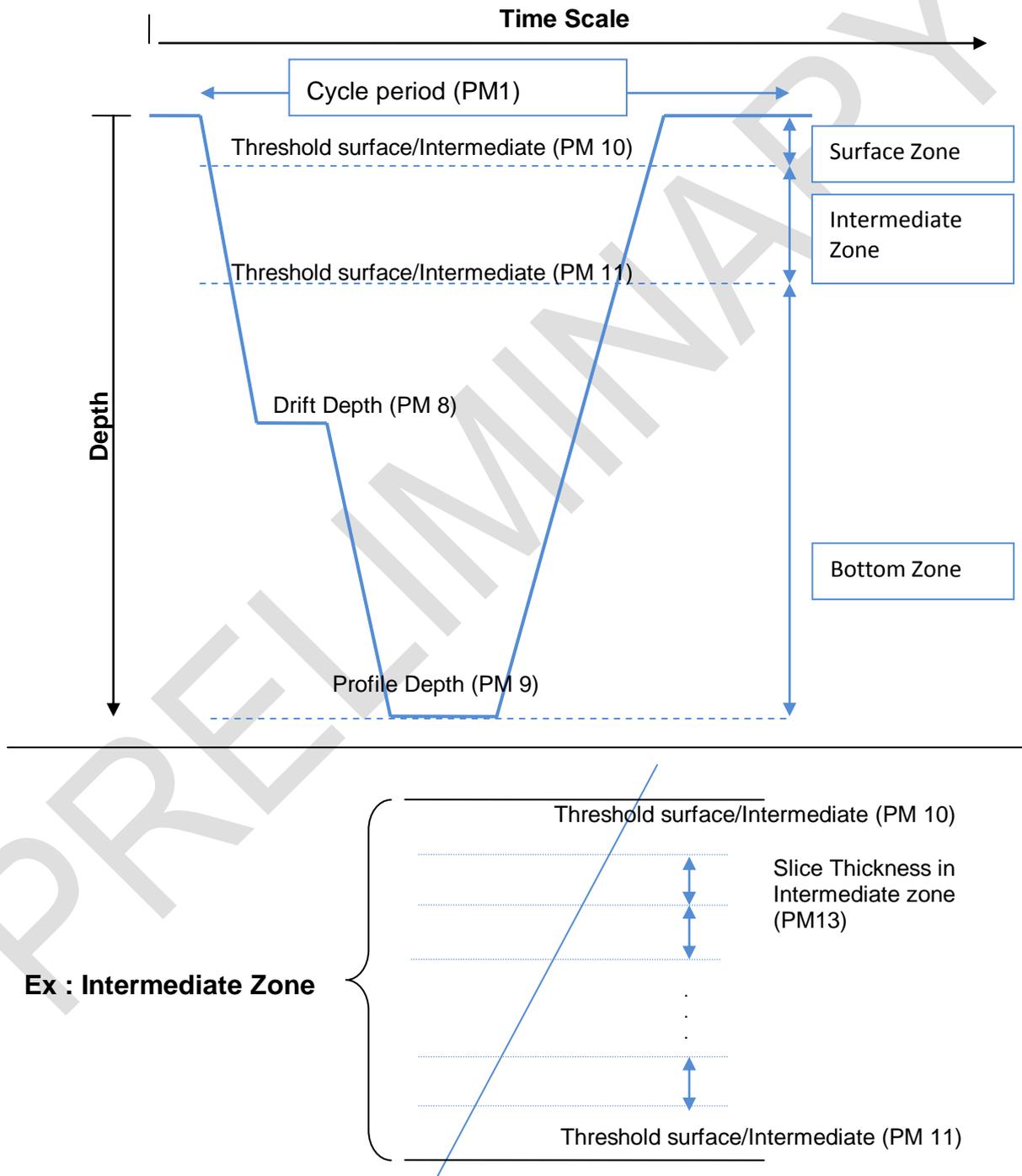


Figure 6- Zone & Slice thickness description

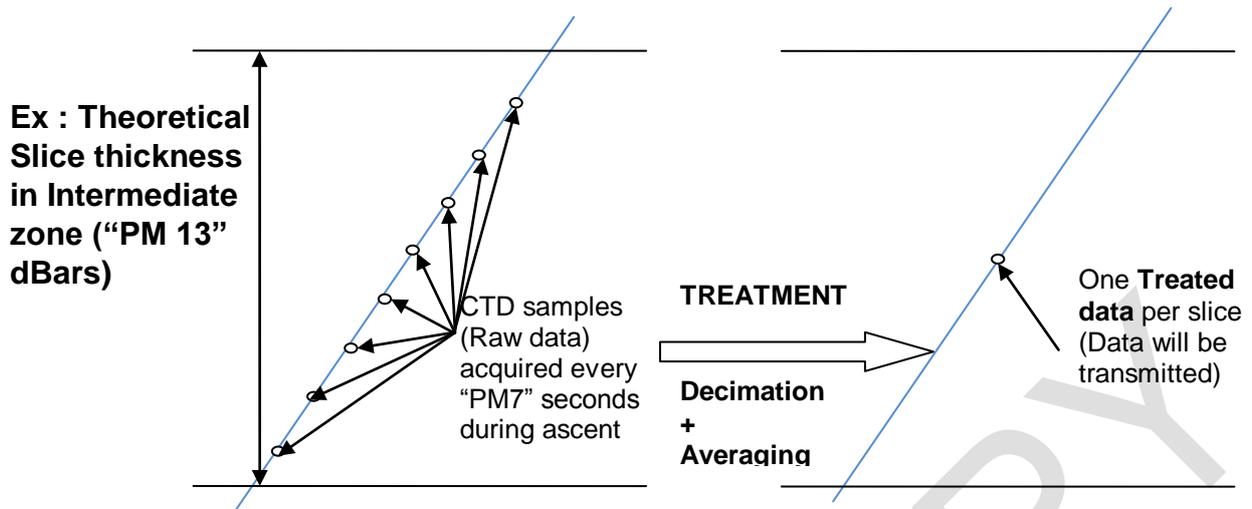


Figure 7 - Treatment description

## 6.10.2 Decimation

All raw data included in one theoretical CTD slice (defined with mission command depending on zone threshold and slice thickness in each zone) are filtered before proceed to averaging operation. Filter condition is that CTD samples must have 0.5 dBar pressure variation with last kept CTD sample sample to be kept.

Example : 5 dBar slice thickness in bottom zone (defined with MC17) from 20 to 15 dBar.

CTD sample rank	CTD sample Pressure (raw data) in theoretical slice	CTD sample temperature	CTD sample salinity	Last previous Kept sample pressure	Pressure difference with previous sample	Keep after decimation
0	19.9 dBars	17.312	33900	-	-	Yes (1st sample in slice)
1	19.3 dBars	17.314	33901	19.9	$19.9 - 19.3 = \underline{0.6}$	Yes
2	18.9 dBars	17.317	33903	19.3	$19.3 - 18.9 = 0.4$	No
3	18.6 dBars	17.319	33904	19.3	$19.3 - 18.6 = \underline{0.7}$	Yes
4	18.1 dBars	17.320	33905	18.6	$18.6 - 18.1 = \underline{0.5}$	Yes
5	17.5 dBars	17.320	33906	18.1	$18.1 - 17.5 = \underline{0.6}$	Yes
6	17.1 dBars	17.322	33907	17.5	$17.5 - 17.1 = 0.4$	No
7	16.5 dBars	17.329	33909	17.5	$17.5 - 16.5 = \underline{1.0}$	Yes
8	16.1 dBars	17.338	33910	16.5	$16.5 - 16.1 = 0.4$	No
9	15.6 dBars	17.351	33910	16.5	$16.5 - 15.6 = \underline{0.9}$	Yes
10	15.1 dBars	17.361	33913	15.6	$15.6 - 15.1 = \underline{0.5}$	Yes

Table 9 - Decimation example

### 6.10.3 Averaging

All CTD samples kept after decimation are averaged according to slice thickness (zone and thickness) to create a “Treated Data”. All the treated Data will be transmit by Iridium.

In our example, following sample pressure will be averaged :

19.9, 19.3, 18.6, 18.1, 17.5, 16.5, 15.6 & 15.1

CTD pressure for treated data is : 18.1375 dBar

Transmitted pressure will be **18 dBar**.

CTD temperature sample will be averaged :

17.312, 17.314, 17.319, 17.320, 17.320, 17.329, 17.351, 17.361

CTD temperature for this treated data is : 17.3285 °C

Transmitted pressure will be **17.328 °C**.

CTD salinity sample will be averaged :

33900, 33901, 33904, 33905, 33906, 33909, 33910, 33913

CTD temperature for this treated data is : 33906 mPSU

Transmitted pressure will be **33906 mPSU**.

### 6.11 Parameters Data message (type = 5)

This message contains float’s mission and technical parameters

Data	Format (bytes)	Resolution
Type (=5)	1	
<b>General information</b>		
Float's time (hh+mm+ss, 1 byte each)	3	
Float's date (dd+mm+yy, 1 byte each)	3	
Cycle number	2	1 cycle
<b>Mission parameters – Next Cycle</b>		
Number of Cycles (PM 0)	2	
Cycle Period (PM 1)	1	Days
Reference Day (PM 2)	1	Hours
Estimated time at the surface (PM 3)	1	Hours
Delay Before Mission (PM 4)	0	Minutes
Descent Sampling Period (PM 5)	1	Seconds
Drift Sampling Period (PM 6)	1	Hours
Ascent Sampling Period (PM 7)	1	Seconds
Drift Depth (PM 8)	2	dBar
Profile Depth (PM 9)	2	dBar
Threshold surface/Intermediate Pressure (PM 10)	2	dBar
Threshold Intermediate /bottom Pressure (PM 11)	2	dBar
Thickness of the surface slices (PM 12)	1	dBar
Thickness of the intermediate slices (PM 13)	1	dBar
Thickness of the Bottom slices (PM 14)	1	dBar

Iridium End Of Life transmission period (PM 15)	2	Minutes
Iridium 2 <sup>nd</sup> session waiting time (PM 16) ("0" means no 2 <sup>nd</sup> session)	2	Minutes
Wait at surface after grounding (PM 17)	1	Minutes
<b>Technical Parameter – Next Cycle</b>		
Max eV activation on Surface (PT 0)	1	10 cs
Max volume eV during descent and repositioning (PT 1)	1	1 cm3
Max duration pump during repositioning (PT 2)	1	10 cs
Duration pump during ascent (PT 3)	1	10 cs
Duration Pump during for surfacing (PT 4)	1	1000 cs
Pressure Delta for positioning (+/-) (PT 5)	1	1 dBar
Max pressure before emergency ascent (PT 6)	2	1 dBar
1st threshold for buoyancy reduction (PT 7)	1	1 dBar
2nd threshold for buoyancy reduction (PT 8)	1	1 dBar
Repositioning threshold (PT 9)	1	-
Grounding mode (PT10)	1	
Max volume before detecting grounding (PT 11)	1	1 cm3
Grounding pressure (PT 12)	2	10 dBar
Grounding switch pressure (PT 13)	1	
Pressure delta during drift (+/-) (PT 14)	1	1 dBar
Not Used (PT 15)	1	-
T_profil_alten (PT 16)	1	-
P_profil_alterne (PT 17)	2	1 Bar
Average descent speed (PT 18)	1	1 mm/s
Pressure increment (PT 19)	1	1 dBar ?
PCutoff CTD pump sensor (PT 20)	1	1 dBar
Oxygen measurement (PT 21)	1	
Ascent End Pressure (PT 22)	1	1 dBar
Average ascent speed (PT 23)	1	1 mm/sec
Float ascent speed control period (PT 24)	1	1 min
Pressure ascent speed control pressure (PT 25)	1	1 dBar
Float descent speed control period (PT 26)	1	1 min
Pressure descent speed control pressure (PT 27)	1	1 dBar
GPS retries (PT 28)	1	
Hydraulic message transmission (0 : no, 1 ; yes) (PT 29)	1	
Coeff A (PT 30)	2	*0,001
Coeff B (PT 31)	2	* (-1)
<b>Complement</b>		
Complement (filled by zeros)	20	
<b>TOTAL</b>	<b>100</b>	

Table 10 - Parameters message

## 6.12 Hydraulic message Ev (type = 6)

This message contains information regarding hydraulic electro-valve actions during past cycle

Data	Nb bytes	Res
Type (=6)	1	
<b>General Information</b>		
Cycle beginning relative day	2	1 day
Cycle beginning hour	2	1 min
<b>Actions during cycle (except )</b>		
Hour (relative to cycle beginning)	2	1 min
Pressure	2	1 dBar
Duration	2	1 cs
Following points	6*14	
<b>Complement</b>		
Complement (filled by zeros)	5	
<b>TOTAL</b>	<b>100</b>	

Table 11 - Hydraulic message EV

## 6.13 Hydraulic message Pump (type = 7)

This message contains information regarding hydraulic pump actions during past cycle

Data	Nb bytes	Res
Type (=7)	1	
<b>General Information</b>		
Cycle beginning relative day	2	1 day
Cycle beginning hour	2	1 min
<b>Actions during cycle (except )</b>		
Hour (relative to cycle beginning)	2	1 min
Pressure	2	1 dBar
Duration	2	1 cs
Following points	6*14	
<b>Complement</b>		
Complement (filled by zeros)	5	
<b>TOTAL</b>	<b>100</b>	

Table 12 - Hydraulic message pump

### 6.14 Life Expiry Message

Life expiry messages are transmitted when the float is drifting on the surface and has completed transmission of all data from the last cycle of the Mission. Life Expiry mode continues until the recovery of the float or depletion of the battery.

These transmissions - unlike other transmissions - occur at “PM15” minutes intervals. The content of the life expiry message is identical to the technical message. This period can be set up to 7200 minutes max (5 days). Minimum recommended value is 5 minutes (only for recovery operations). Period can be set to short period during recovery operations with great care to cost transmission. To reduce float’s transmission during End-Of-Life, this period can be set to high value to decrease transmission cost.

#### 6.14.1 Phase description

Phase indication included in all kind of Iridium messages

Phase number	Phase Name	Description
0	Pre-mission	Mission beginning (1st Iridium session)
1	Restoffset	Float send command “restoffset” command to CTD SBE41 Sensor
2	Buoyancy reduction	Float descending phase at surface (up to PT specific threshold)
3	Descent to parking pressure	Float descend to Parking Pressure depth
4	Parking Drift	Float drift at Parking Depth
5	Descent to profile pressure	Float descend to Profile Depth
6	Drift at Profile Depth	Float drift at Profile Depth
7	Ascent Profile	
8	Satellite transmission	Float transmit all sensor and technical packets

**Table 13 - Phase Number Description**

### 6.15 Iridium commmands

Each mission or technical parameter can be modified with Iridium telecommand. One parameter can be modified with on telecommand. Several telecommands can be send for one cycle.

PM(16) Inter-cycles wait period (min) : User send telecommand that initialize PM16. At each cycle, float’s wait on surface for PM16 values (minutes). This parameter can be set to zero. Once wait is ended, float check if a new telecommand has been sent. If yes, new mission parameter is set with transmitted value and float wait corresponding time. In other case, float begin cycle.

At following cycle, if none telecommand is sent, float waits programmed value (PM16) by last telecommand.

Telecommand has effect on all cycle.

Technical and mission parameters : new parameters are recovered at each cycle (if telecommand has been sent).

So, each new parameter transmitted by telecommand is applied for following cycle.



# ARVOR-DEEP FLOAT USER MANUAL

In a delay of a few minutes, user can check that iridium system send confirmation that message is queued (email coming from [sbdservice@sbd.iridium.com](mailto:sbdservice@sbd.iridium.com) with subject : "SBD Mobile Terminated Message Queued for Unit : xxxxxxxxxxxxxxxx (here xx replace IMEI number)

Mail from iridium will indicate :

*"The following mobile-terminated message was queued for delivery:*

*IMEI: 3000001001xxxxxx*

*Time: Thu Apr 29 12:00:13 2010*

*Attachment Filename: update.sbd*

*Attachment Size: 10*

*The MTMSN is 2, and the message is number 1 in the queue."*

At this step, message is queued and ready to be treated by float at next float surfacing.

**Important : Telecommand file size must be less than 30 bytes**

### 7 SPECIFICATIONS

- Storage

Temperature range..... -20°C to +50°C

Storage time before expiry .....up to 1 year

- Operational

Temperature range..... 0°C to +40°C

Pressure at drift depth ..... 40 bar to 412 bar

Depth maintenance accuracy ..... ± 3 bar typical (adjustable)

Survival at sea .....up to 5 years

Maximum number of cycles.....up to 150 cycles

- Mechanical

Length

with antenna .....#219 cm

Diameter

casing .....15 cm

damping disk ..... 25 cm

Weight.....26 kg

- Sensors

Salinity

range..... 10 to 42 PSU

initial accuracy ..... ± 0.005 PSU

resolution..... 0.001 PSU

Temperature

range... ..... -3°C to +32°C

initial accuracy .....± 0.002°C

resolution.....0.001°C

Pressure

range..... 0 bar to 7000 dbar

initial accuracy ..... ± 2.4 dbar\*

resolution.....0.1 dbar

Offset adjusted when surfacing

Oxygen (C1Phase, C2Phase & temperature)

Range (C1Phase, C2Phase)..... -40.000° to 90.000°

initial accuracy ..... 0.001°

Range (Temperature)..... -5.000° to 60.000°

initial accuracy ..... 0.001°

(\*) offset has to be adjusted at each surfacing

### **8 ARVOR-DEEP OPERATING PRINCIPLE**

Movement of the float through its profile is accomplished by a pump and valve system. The pump transfers oil from the inner reservoir to the outer bladder. Oil moves back to the reservoir when the valve is opened- -driven by the difference between the float's internal and external pressures.

The float's speed of ascent oscillates. This oscillation is due to the way in which the float's controller regulates its speed. The controller, using depth measurements from the float's pressure sensor, calculates the change in depth over a set period of time. With this information, the controller determines the float's speed.

When ascending, if the calculated speed is lower than desired, the pump is activated for about 10 seconds, pumping oil into the outer bladder. This produces an increase in buoyancy, which increases the speed of ascent.

As the float rises to shallower depths, its buoyancy decreases, causing the ascent speed to also decrease. When the calculated speed is too low, the pump is activated again.

This cycle repeats until the float reaches the surface.

The same regulating method is used to control the float's descent speed, by opening the valve and allowing oil to flow from the external bladder to the internal reservoir.

#### **Why does ARVOR-DEEP's speed decrease as it ascends?**

The buoyancy of a float is determined principally by its mass and its volume, but another factor, hull compressibility, also plays an important role. As ARVOR-DEEP ascends, the decrease in water density reduces the float's buoyancy. At the same time, the decrease in water pressure causes ARVOR-DEEP's hull to expand, which increases the float's buoyancy. The two effects tend to counteract each other.

Because ARVOR-DEEP's compressibility is actually less than that of sea water, the decrease in buoyancy due to decreasing water density is greater than the increase in buoyancy due to hull expansion. This causes ARVOR-DEEP's speed of ascent to decrease as it rises in the water column.

Conversely, as the float descends, the increasing water density increases the buoyancy more than the decreasing buoyancy from hull compression. This causes ARVOR-DEEP's speed of descent to slow as it goes deeper.

To reduce the probability of contact with ships, ARVOR-DEEP's target speed during the initial stage of descent is high at shallow depths. This minimizes the time during which the float is at risk of damage.

To slow the float's descent, its controller is programmed with a series of depths at which the descent speed is halved until it reaches the target depth.

## 9 LITHIUM BATTERY

All batteries, both lithium batteries and batteries with other chemical elements, contain large quantities of stored energy. This is, of course, what makes them useful, but it also makes them potentially hazardous.

If correctly handled, neither alkaline nor lithium batteries present any risk to humans or the environment. Improper handling of these batteries presents potential risks to humans, but does not present an environmental risk.

The energy stored in a battery cell is stored in chemical form. Most batteries contain corrosive chemicals. These chemicals can be released if the cells are mishandled. Mishandling includes:

- short-circuiting the cells;
- (re)charging the cells;
- puncturing the cell enclosure with a sharp object;
- exposing the cell to high temperatures.

**WARNING: BOTH ALKALINE AND LITHIUM BATTERIES MAY EXPLODE, PYROLIZE OR VENT IF MIS-HANDLED. DO NOT DISASSEMBLE, PUNCTURE, CRUSH, SHORT-CIRCUIT, (RE)CHARGE OR INCINERATE THE CELLS. DO NOT EXPOSE CELLS TO HIGH TEMPERATURES.**

The lithium thionyl chloride cells used in ARVOR-DEEP floats incorporate sealed steel containers, warning labels and venting systems to guard against accidental release of their contents.

**WARNING: IF A BATTERY SPILLS ITS CONTENTS DUE TO MISHANDLING, THE RELEASED CHEMICALS AND THEIR REACTION PRODUCTS INCLUDE CAUSTIC AND ACIDIC MATERIALS, SUCH AS HYDROCHLORIC ACID (HCL) IN THE CASE OF LITHIUM THIONYL CHLORIDE BATTERIES, AND POTASSIUM HYDROXIDE (KOH) IN THE CASE OF ALKALINE BATTERIES. THESE CHEMICALS CAN CAUSE EYE AND NOSE IRRITATION AND BURNS TO EXPOSED FLESH.**

The hazard presented by these chemicals is comparable to that presented by common domestic cleaning materials like bleach, muriatic acid or oven cleaner.

Inevitably, the battery contents will eventually be released into the environment, regardless of whether the cells are deliberately dismantled or simply disintegrate due to the forces of nature. Because of their highly reactive nature, battery materials disintegrate rapidly when released into the environment. They pose no long-term environmental threat. There are no heavy metals or chronic toxins in ARVOR-DEEP's lithium cells. Indeed, a recommended safe disposal method for thionyl chloride lithium cells is to crush them and dilute them in sufficient quantities of water.

Discharged batteries pose a greatly reduced threat, as the process of discharging them consumes the corrosive chemicals contained in them.

In summary, ARVOR-DEEP's lithium battery poses no significant or long-term environmental threats. Any threats that they do present, are short-term threats to the safety of persons mishandling the cells. These safety threats are similar to those of other common household-use materials. These threats are reduced when the cells are discharged - and exist only if the cells are mishandled in extreme ways. These threats are the same as those presented by the alkaline cells widely used by consumers.

## 10 GLOSSARY

### **ARVOR-DEEP**

Name given to the drifting profiler developed by **nke** and IFREMER.

### **BT**

Bluetooth

### **CPU**

Central Processing Unit. In the context of ARVOR-DEEP, this term denotes the board that ensures the running and control of the system.

### **COM1, COM2.**

Serial communication ports.

### **CTD**

Celerity (for salinity), Temperature, Depth and Oxygen

### **dbar.**

1/10 bar = 1 decibar Unit of pressure used for ARVOR-DEEP. It roughly corresponds to a depth of 1m.

### **IFREMER**

Institut Français pour la Recherche et l'Exploitation de la MER (French Institute for the Research and the Exploitation of the Sea).

### **Mission**

The portion of ARVOR-DEEP's life that consists of a number of repeating cycles of descent, submerged drift, ascent and data transmission.

### **PC**

Personal Computer; IBM-PC compatible.

### **PM**

Mission Parameters set

### **RS232**

Widely recognized standard for the implementation of a serial data communication link.

### **Triplet**

Set of four measurements (Salinity, Temperature, Depth and dissolved oxygen) all taken at the same time.

### **VT52, VT100**

Video Terminal, type 52 or 100

Computer terminals developed by Digital Equipment Corporation (DEC). They are considered standard in the field.

*Fabriqué par / Manufactured by*



PRELIM

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